



US009458877B2

(12) **United States Patent**
Bouwer

(10) **Patent No.:** **US 9,458,877 B2**
(45) **Date of Patent:** **Oct. 4, 2016**

(54) **MULTI-DIRECTIONAL ELASTOMERIC DAMPENED BALL JOINT ASSEMBLY**

(56) **References Cited**

U.S. PATENT DOCUMENTS

(71) Applicant: **The Boeing Company**, Chicago, IL (US)

2,885,248 A * 5/1959 White F16C 11/0604 264/242

(72) Inventor: **Scott Hendrik Bouwer**, Wilmington, DE (US)

3,778,189 A 12/1973 Ferris

3,862,812 A 1/1975 Gornadt et al.

4,439,055 A * 3/1984 Quigg et al. 403/330

4,533,274 A * 8/1985 Moore 403/31

4,895,354 A 1/1990 Byrnes

5,601,408 A 2/1997 Hunter et al.

5,951,061 A 9/1999 Arlt, III et al.

7,097,169 B2 8/2006 Mueller

8,016,324 B2 * 9/2011 Gutierrez-Lemini

et al. 285/223

8,038,177 B2 * 10/2011 Gutierrez-Lemini

et al. 285/223

2009/0268997 A1 10/2009 Cunningham et al.

(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 323 days.

(21) Appl. No.: **13/749,495**

OTHER PUBLICATIONS

(22) Filed: **Jan. 24, 2013**

International Search Report, dated Mar. 21, 2014, regarding Application No. PCT/US2013/075249, 7 pages.

(65) **Prior Publication Data**

International Search Report, dated Jul. 28, 2015, regarding Application No. PCT/US2013/075249, 4 pages.

US 2014/0205364 A1 Jul. 24, 2014

* cited by examiner

(51) **Int. Cl.**

B64D 1/22 (2006.01)

F16C 11/06 (2006.01)

F16F 1/40 (2006.01)

Primary Examiner — Jonathan Masinick

(74) Attorney, Agent, or Firm — Yee & Associates, P.C.

(52) **U.S. Cl.**

CPC **F16C 11/06** (2013.01); **B64D 1/22** (2013.01); **F16F 1/40** (2013.01); **F16F 2230/14** (2013.01); **Y10T 403/32614** (2015.01)

(57)

ABSTRACT

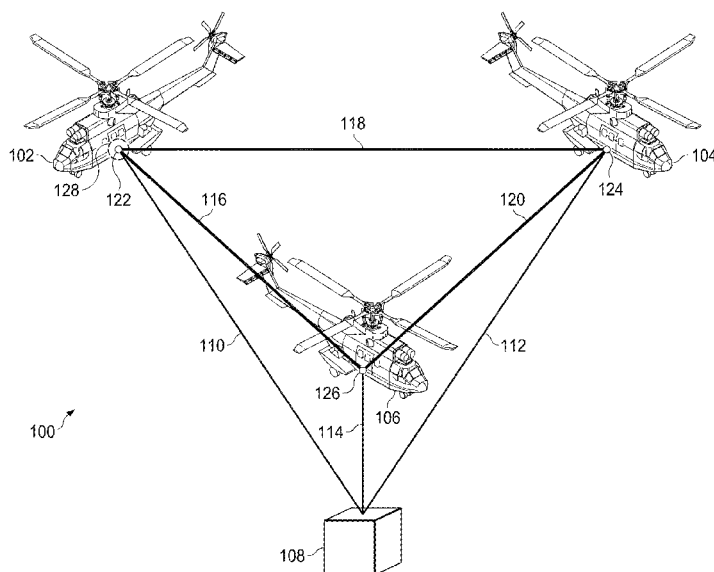
A method and apparatus for reducing a force. An apparatus comprises a multi-directional joint assembly and a damper associated with the multi-directional joint assembly. The multi-directional joint assembly has a first end and a second end. The first end and the second end move relative to each other. The damper is comprised of a number of elastomeric layers and a number of rigid layers interspersed with each other reducing at least one of a force and a moment.

(58) **Field of Classification Search**

CPC F16C 11/06; F16C 11/08; F16C 11/083; Y10T 403/32713; Y10T 403/32721; Y10T 403/32729; B64D 1/22

USPC 403/132, 133, 135, 138, 144
See application file for complete search history.

14 Claims, 14 Drawing Sheets



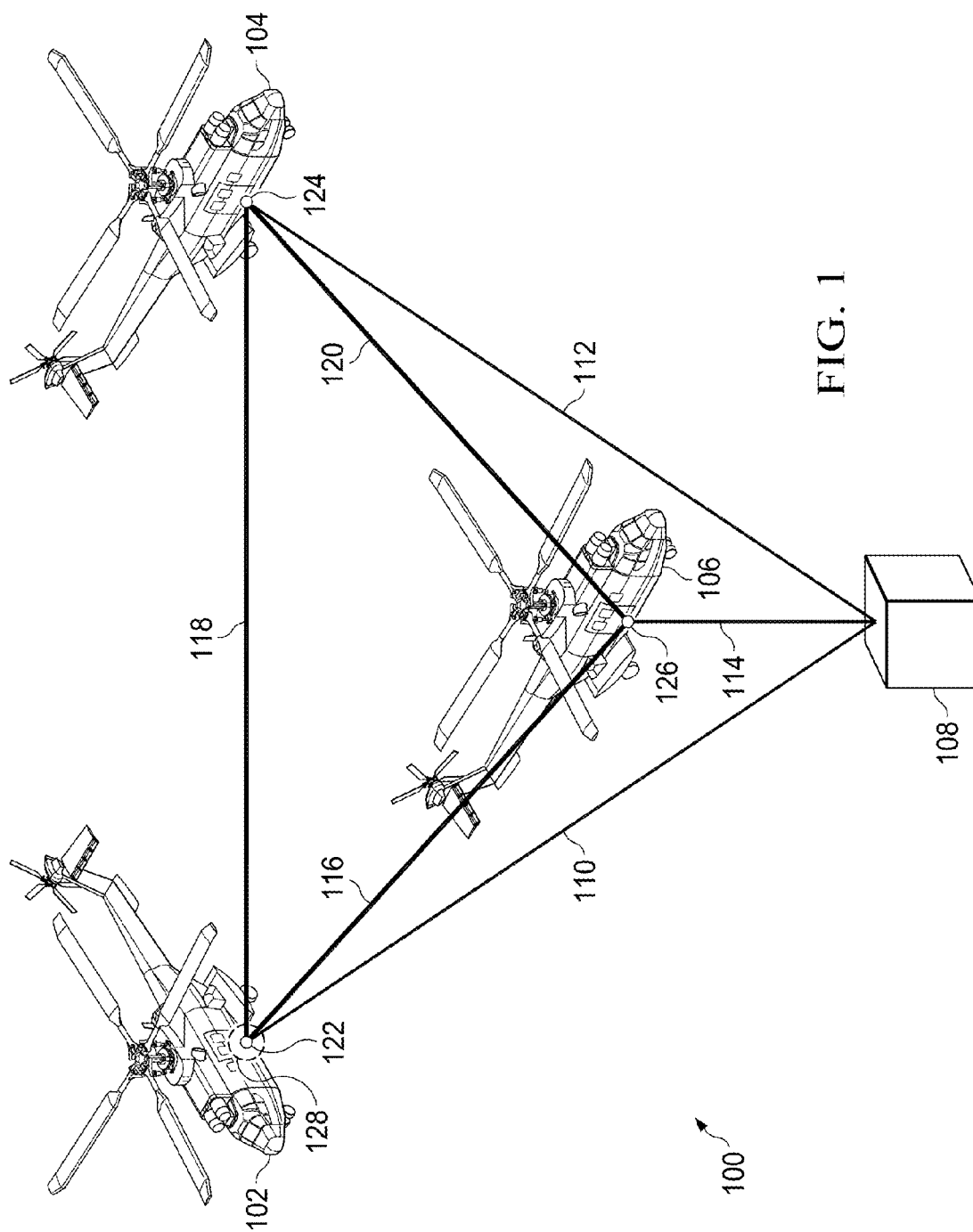
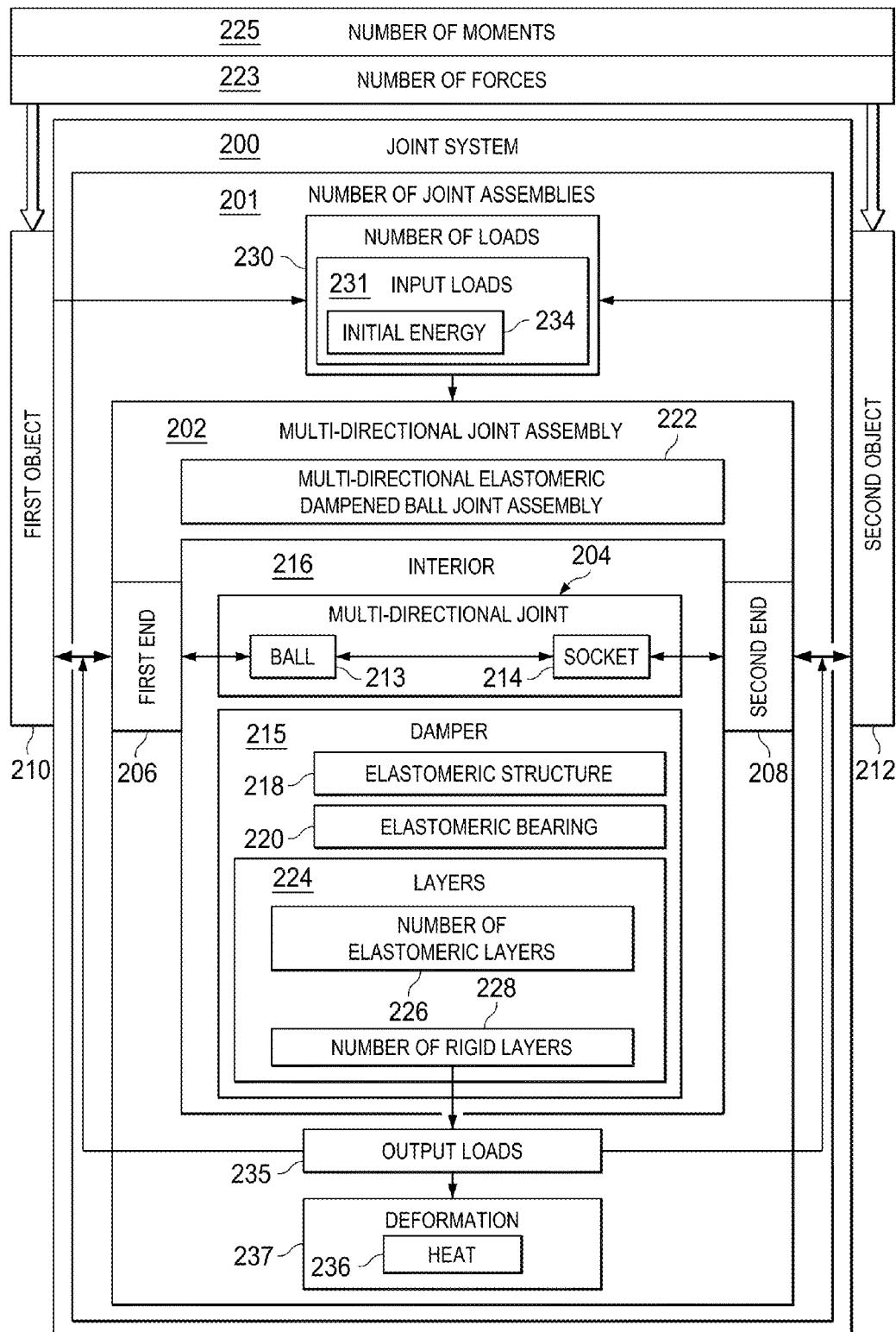
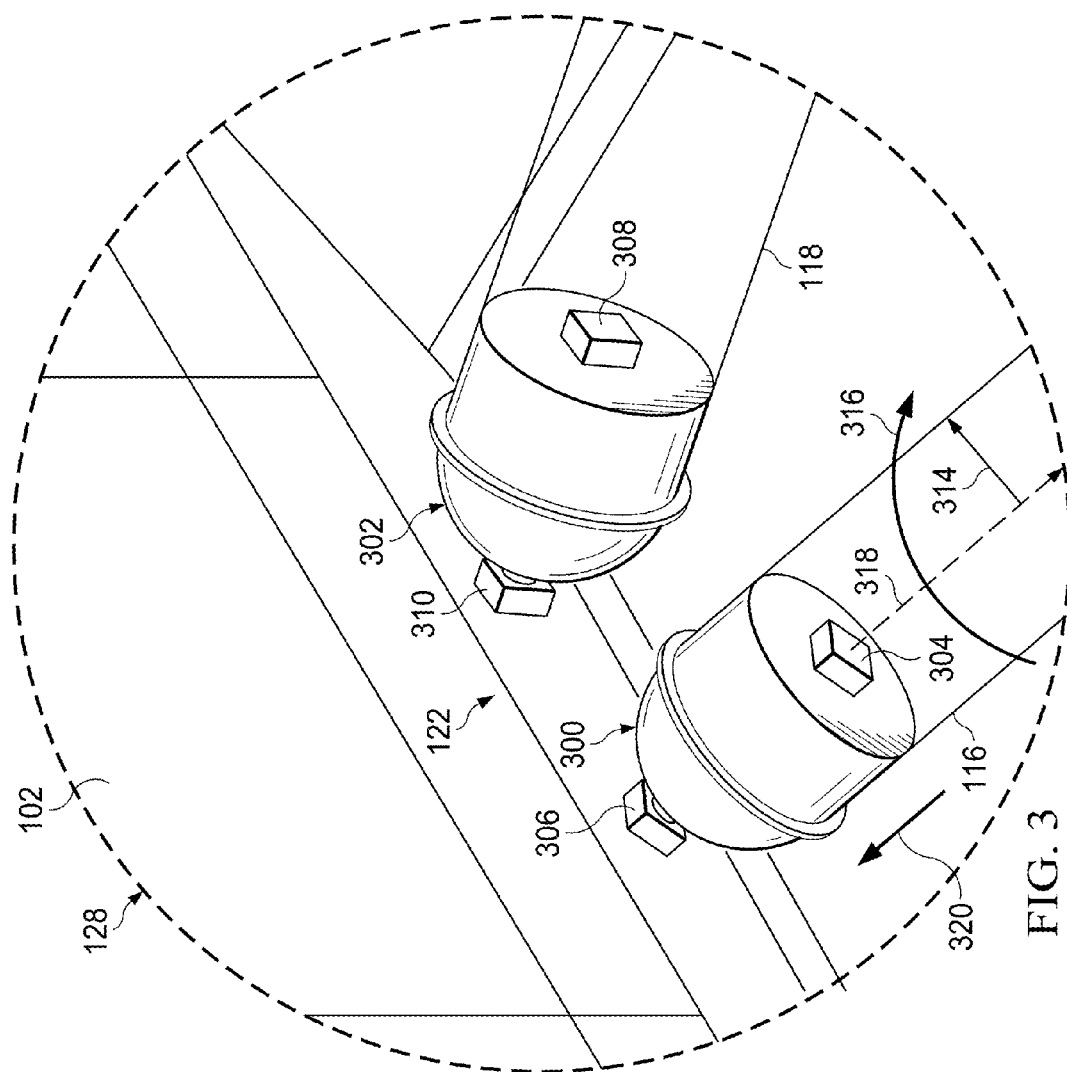


FIG. 2





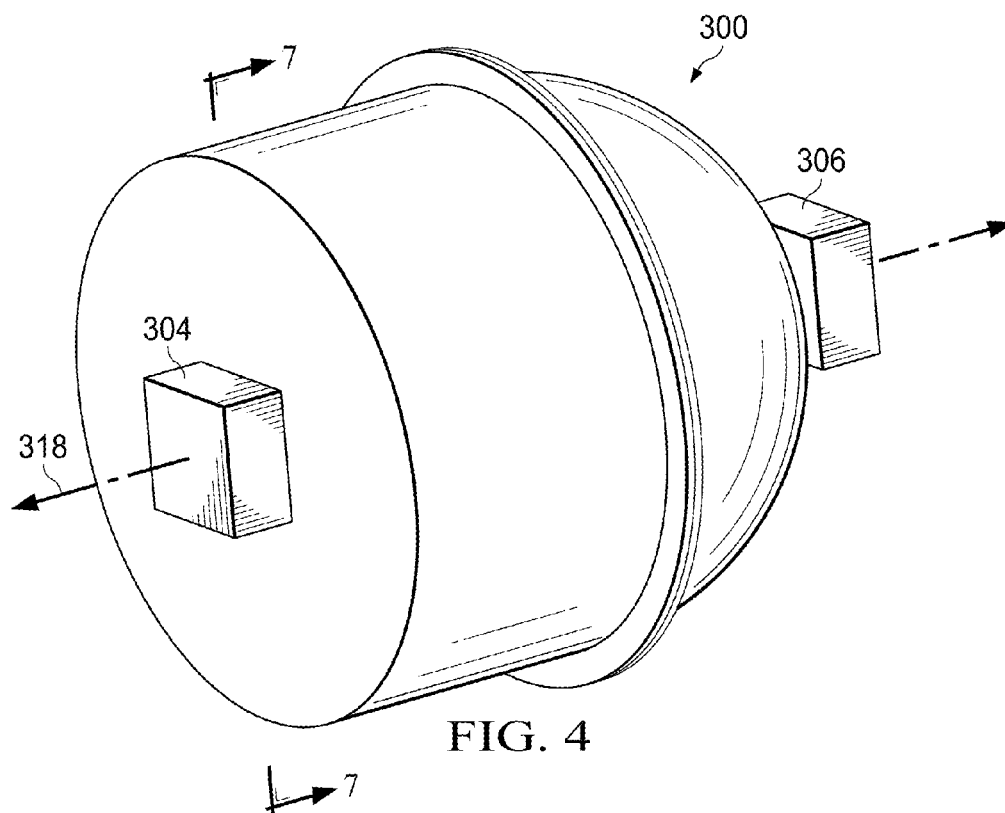


FIG. 4

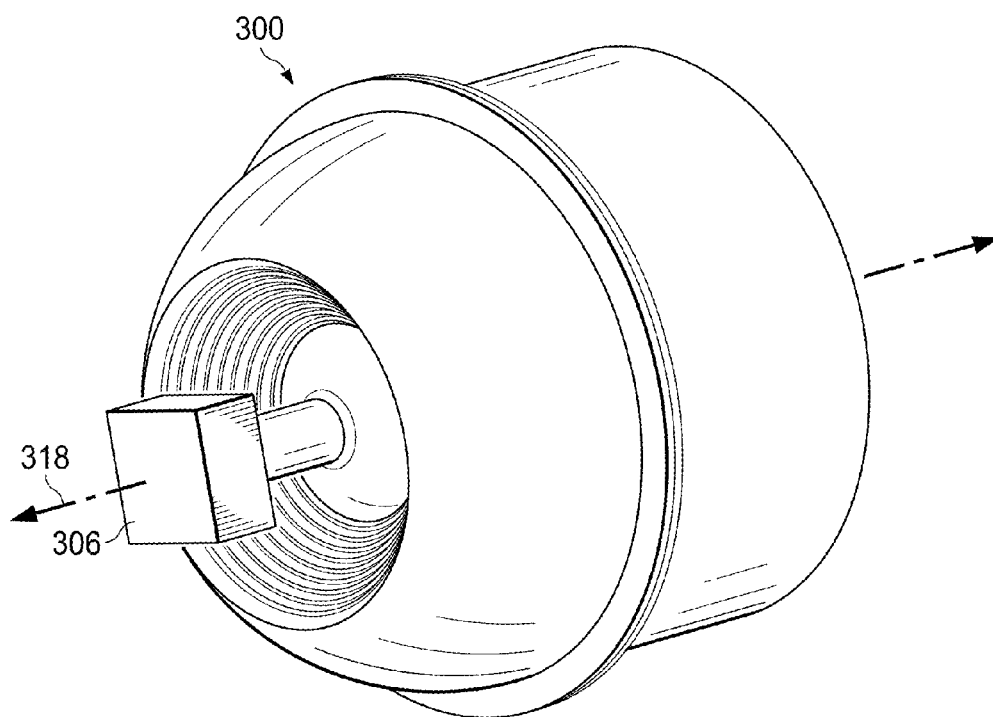


FIG. 5

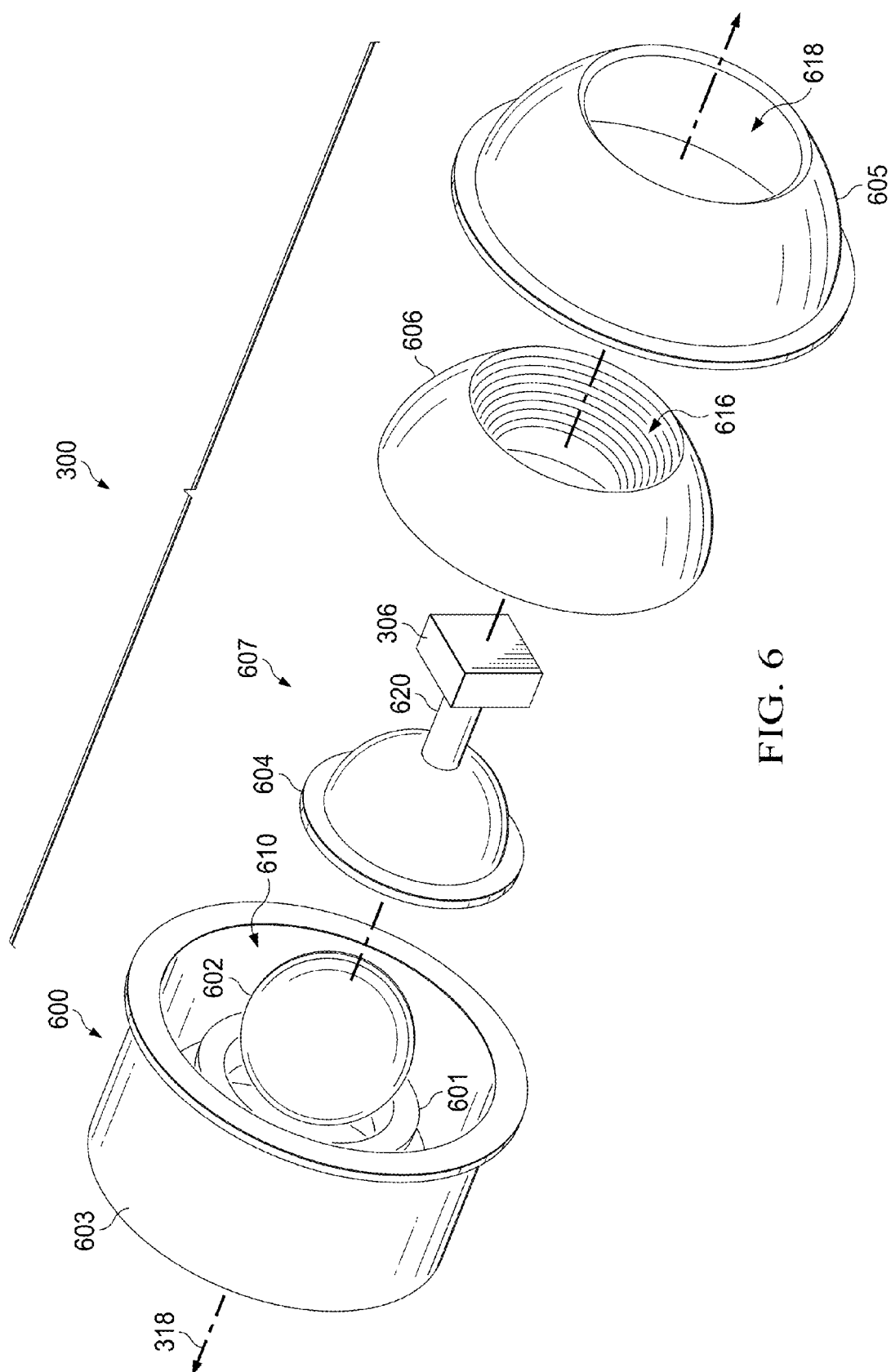


FIG. 6

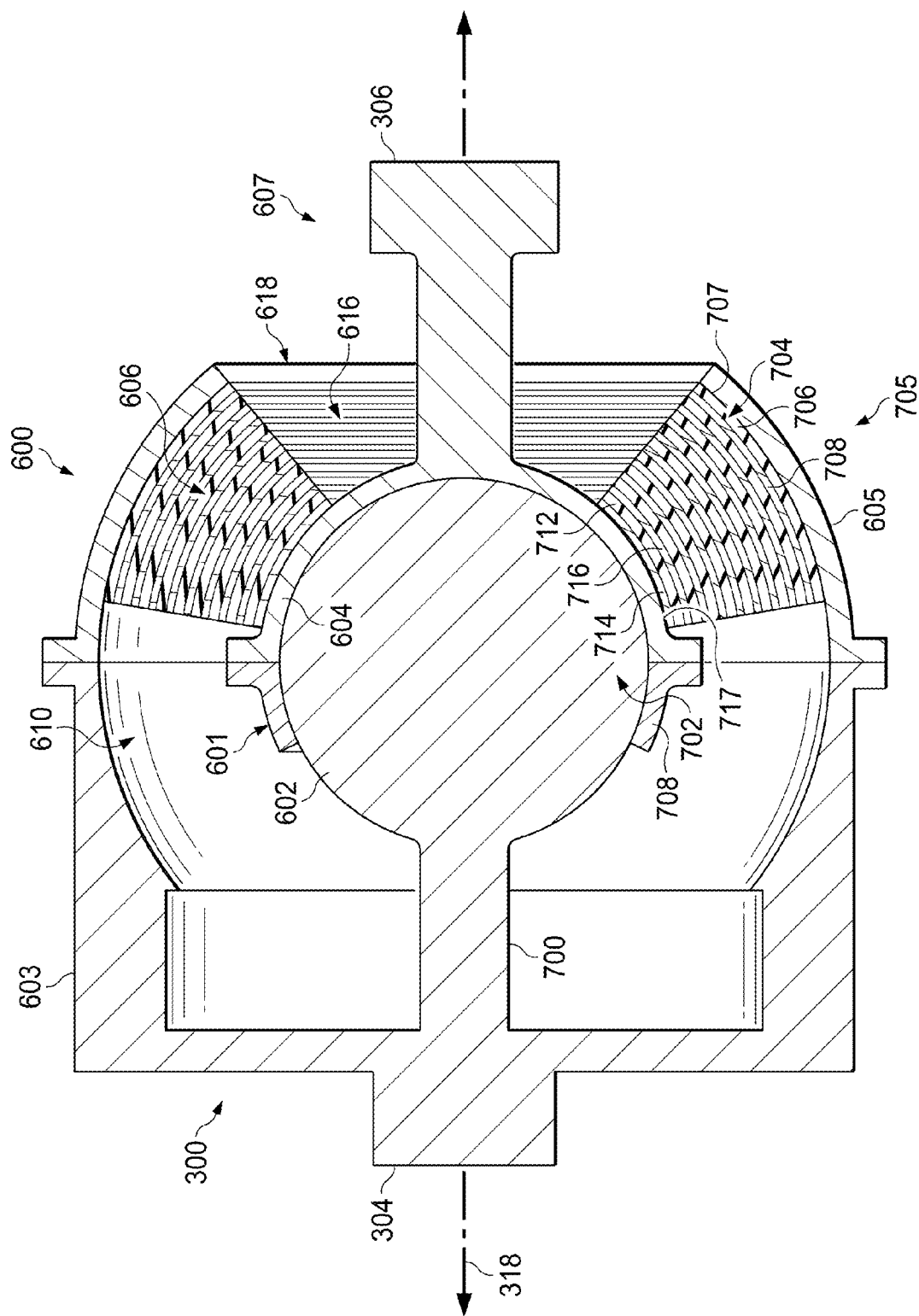


FIG. 7

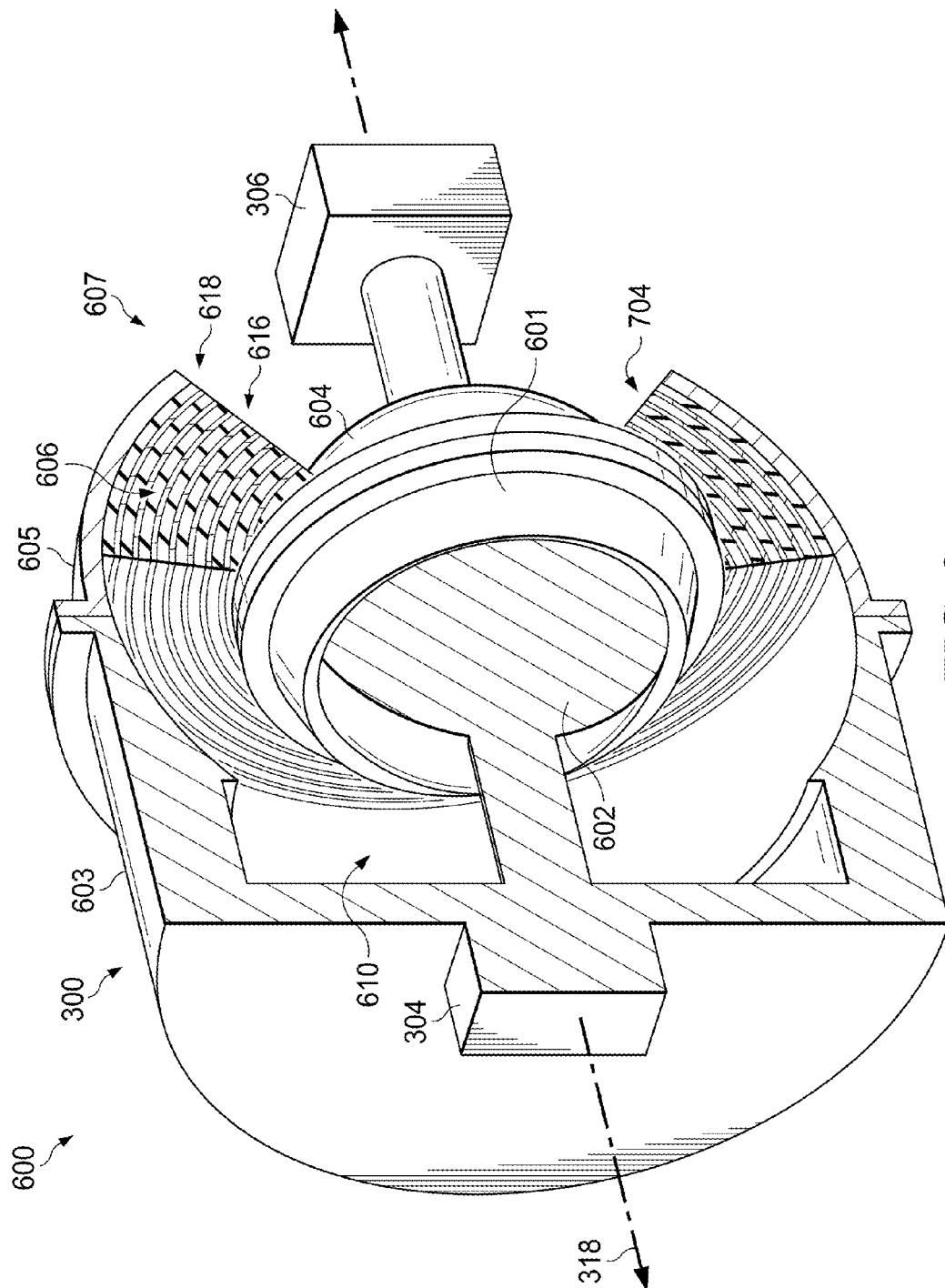


FIG. 8

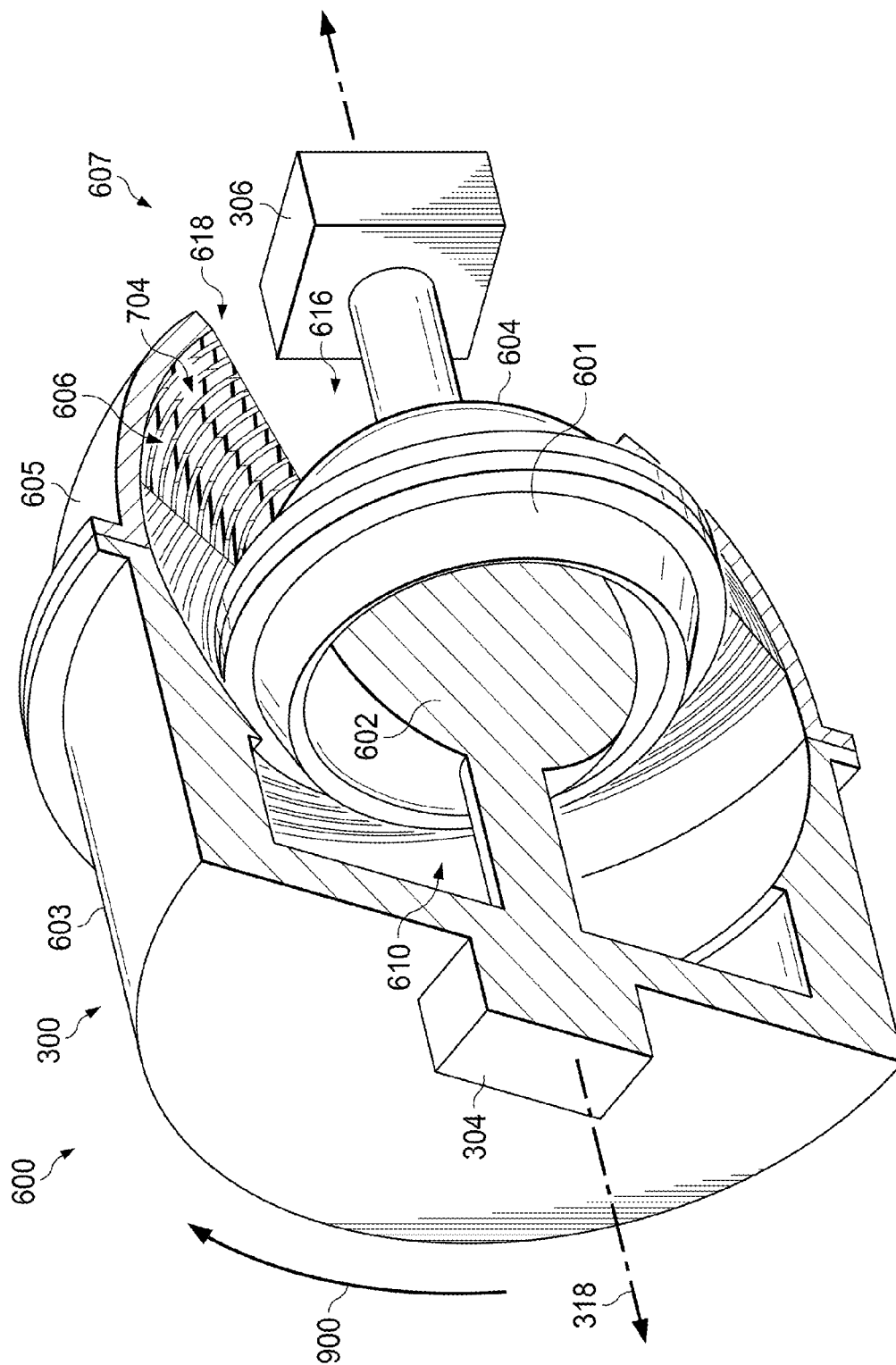
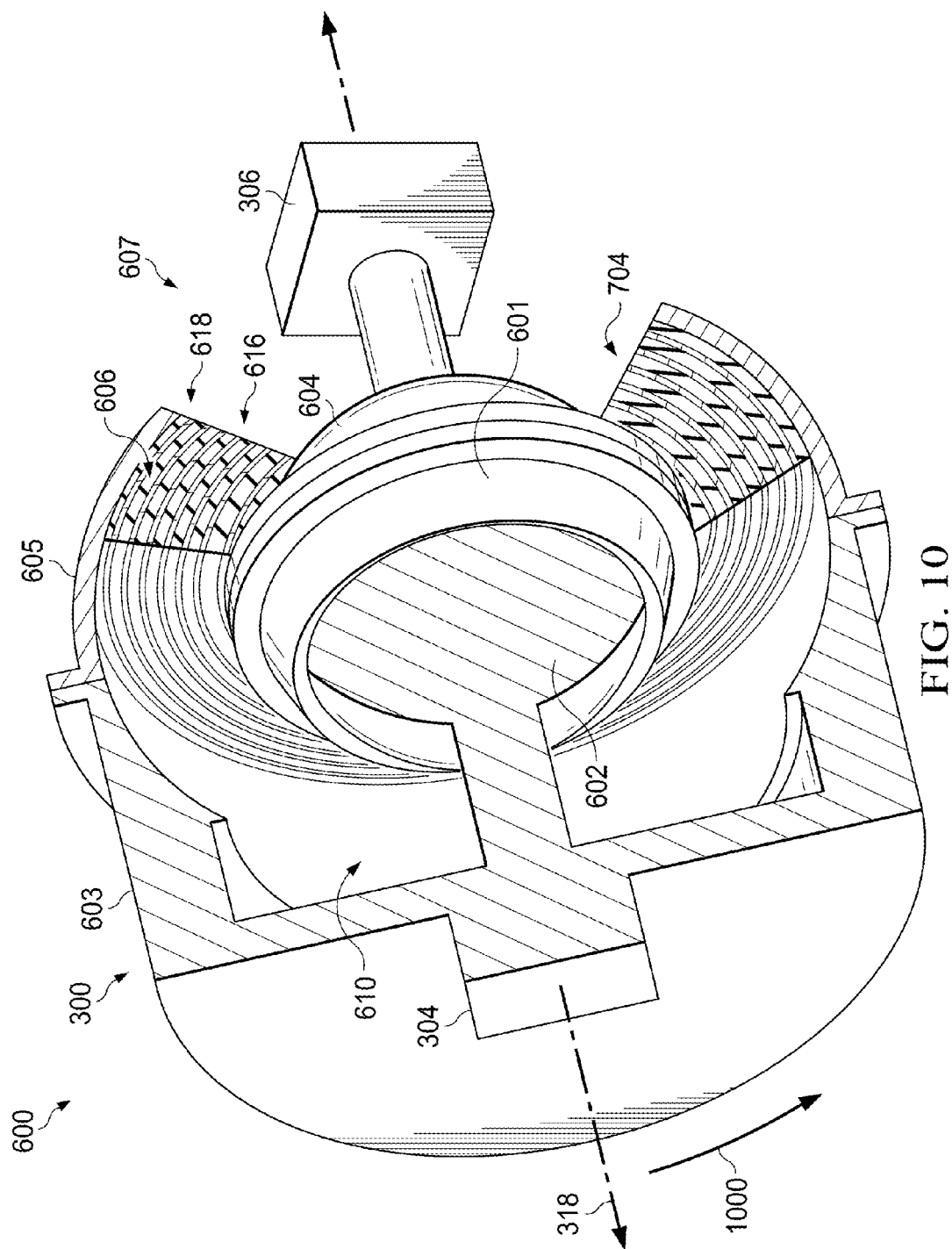


FIG. 9



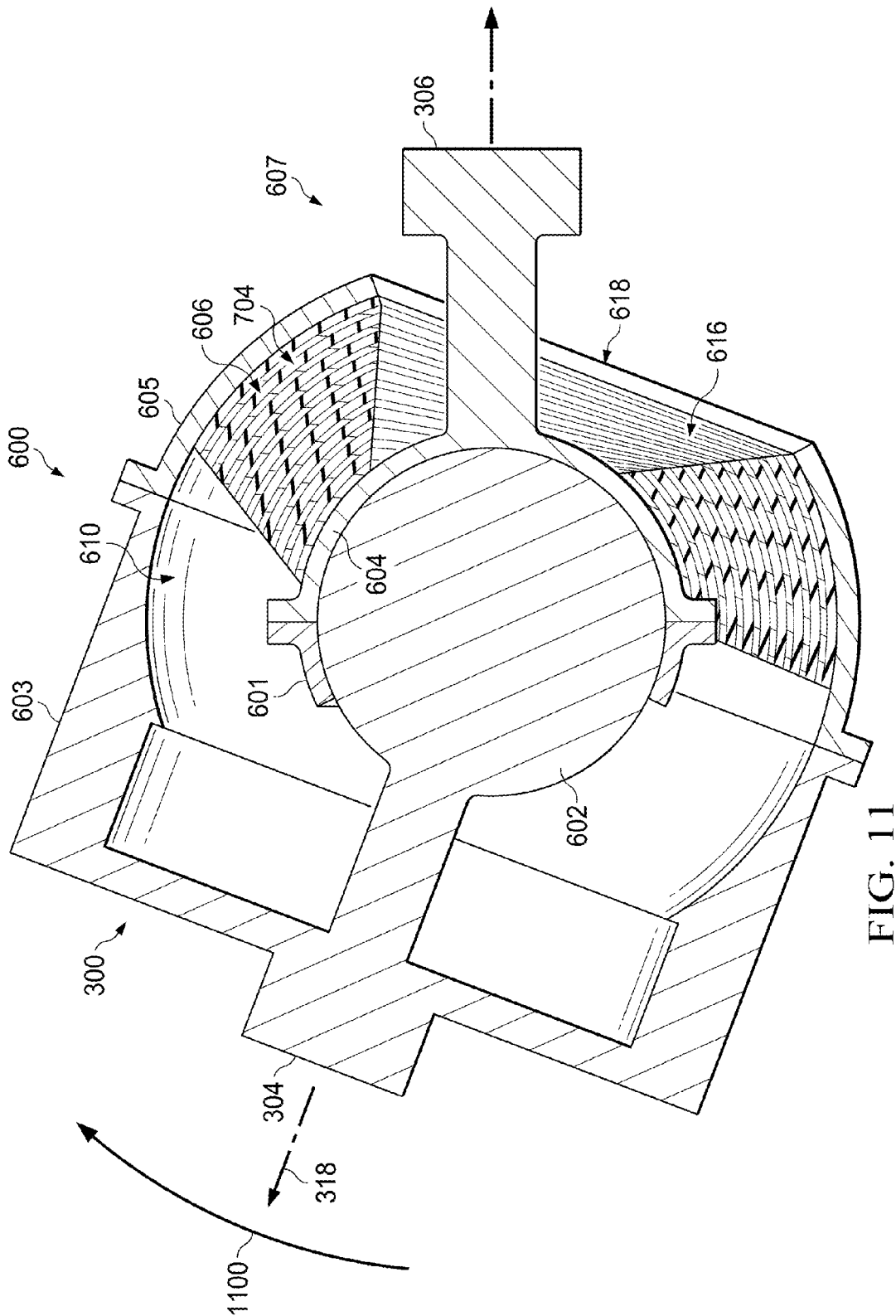
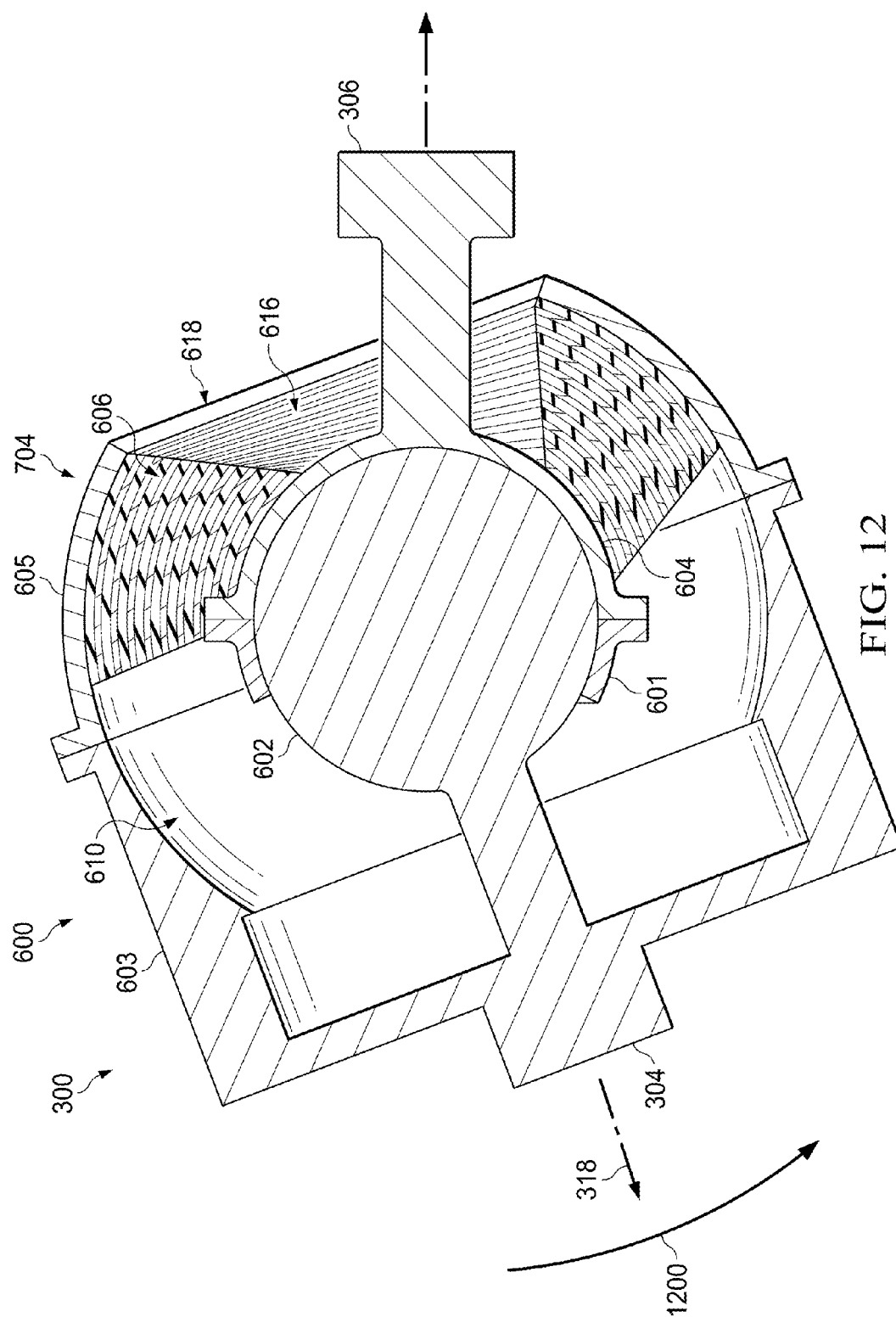


FIG. 11



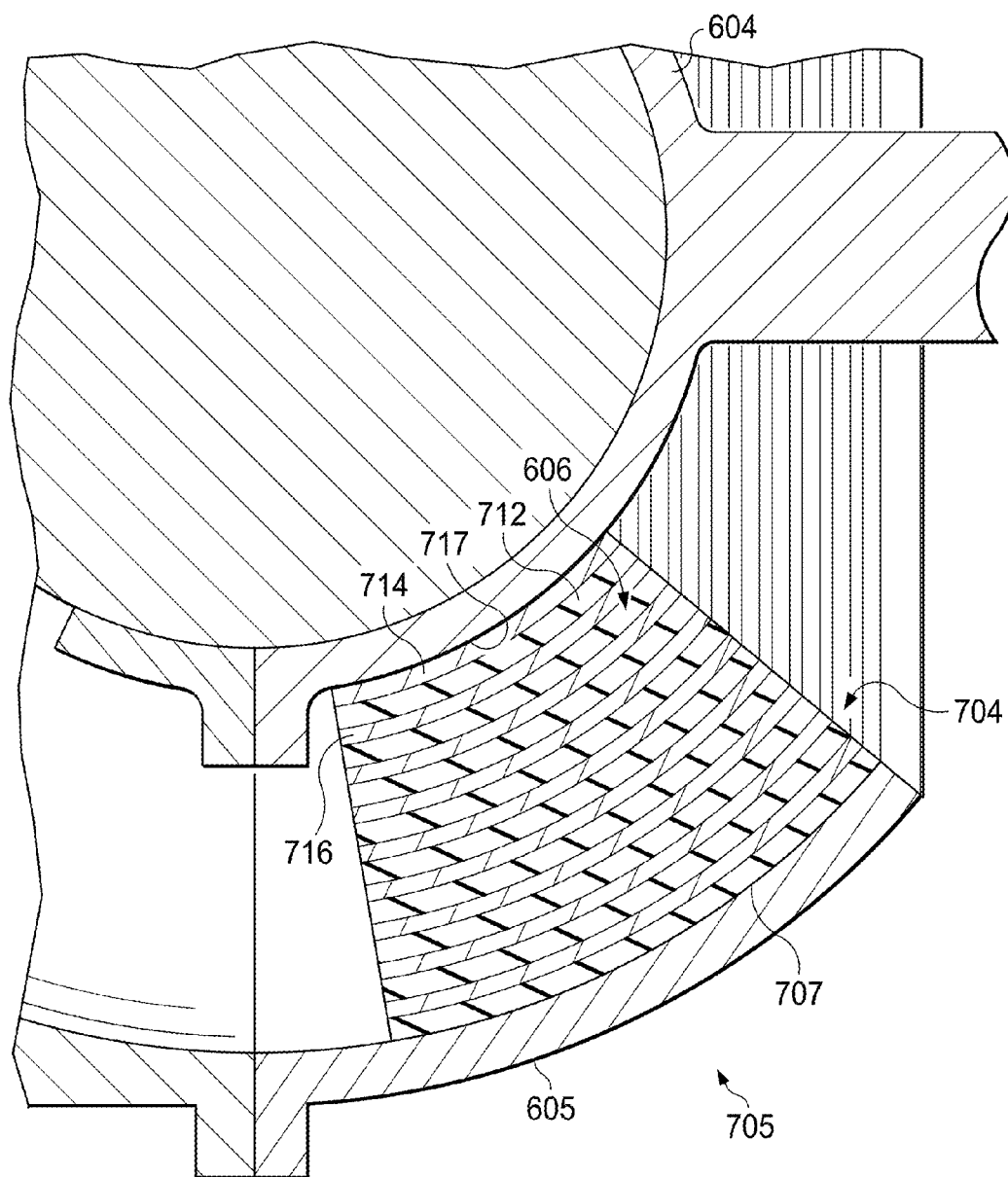


FIG. 13

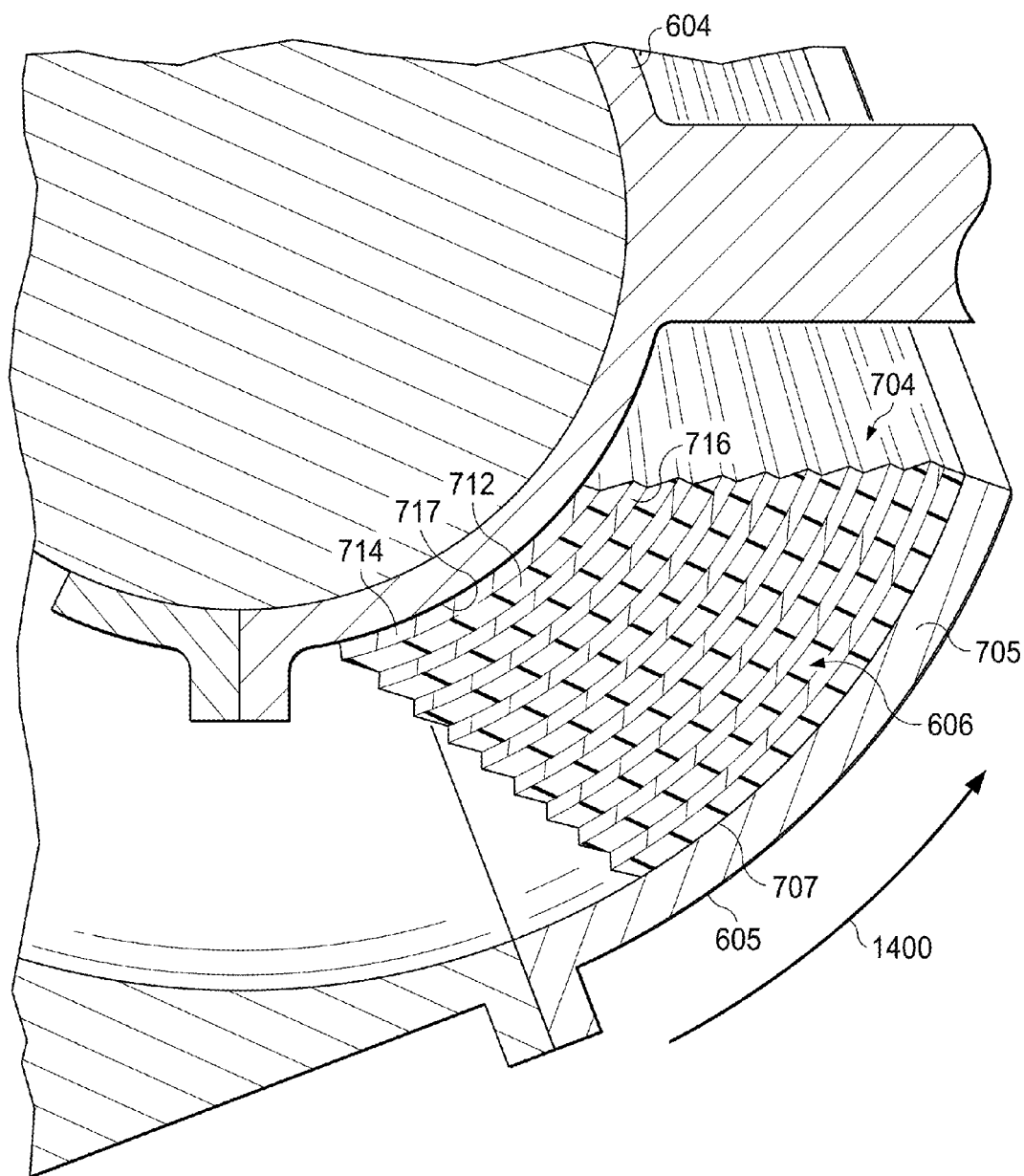


FIG. 14

FIG. 15

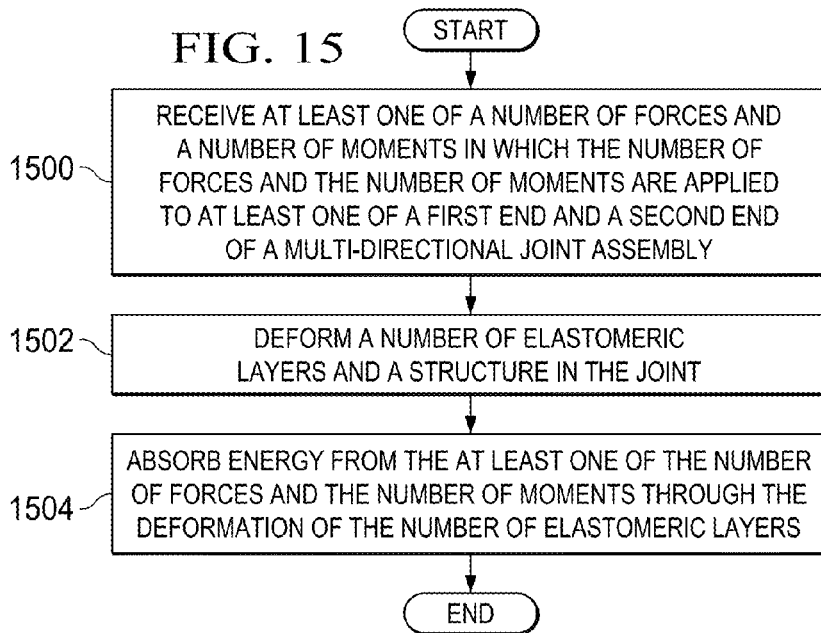
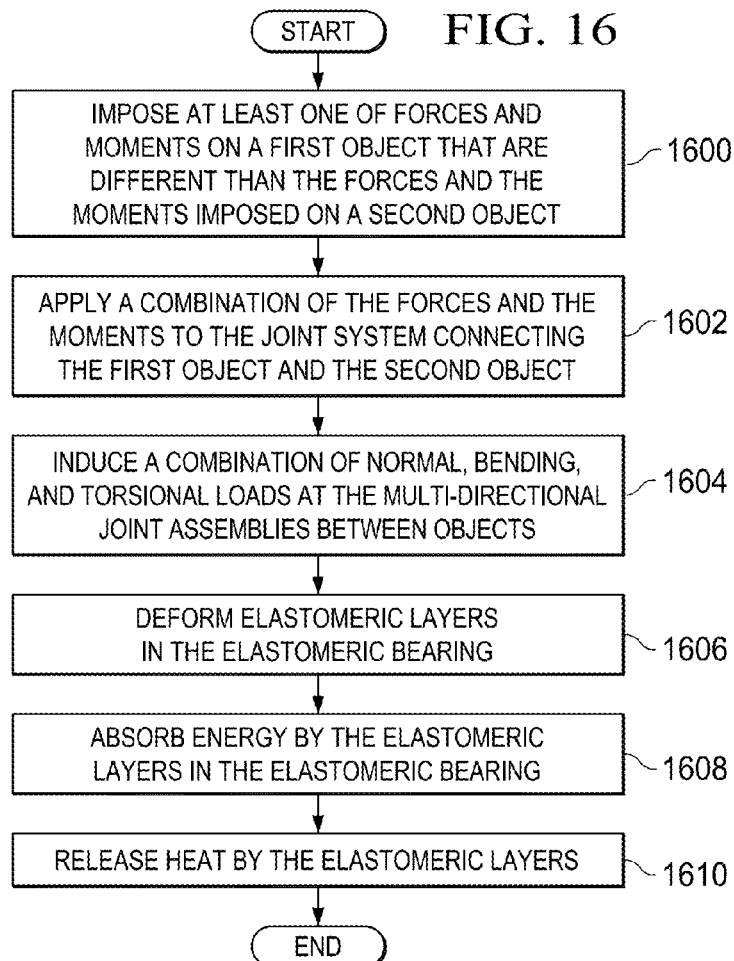


FIG. 16



1

MULTI-DIRECTIONAL ELASTOMERIC DAMPENED BALL JOINT ASSEMBLY

BACKGROUND INFORMATION

1. Field

The present disclosure relates generally to structures and, in particular, to structures carrying loads. Still more particularly, the present disclosure relates to a method and apparatus for carrying loads while allowing controlled displacement of the structures carrying the loads.

2. Background

With mechanical systems, different objects may be connected to each other. For example, a bridge may have towers, parts of a deck, suspension cables, and other components that are connected to each other. In some cases, the connection between objects may allow for movement, expansion, or contraction of the objects. The point of connection of two or more objects is a joint. In some cases, joints connecting two objects together may be multi-directional joints that allow movement in more than one direction.

When objects are connected to each other, dampers may be used. A damper is a physical structure connected to the objects. When a load is carried through the damper, the damper allows a controlled amount of deflection in at least one direction which reduces any force applied in that direction. In other words, a damper may arrest movement in certain directions but allow deflection and reduced loads in other directions. This process constrains relative motion between the objects in response to applied loads and forces while reducing the forces carried through the system in the directions that are able to deflect.

A damper, used with a load bearing joint, may constrain the relative motion between objects to only a few degrees of freedom. For example, a hydraulic damper, such as an automotive shock absorber, may be used to allow one-dimensional movement of a point along a line. In another example, a cylindrical elastomeric bearing may accommodate rotation about a fixed axis.

A damper may limit motion to certain degrees of freedom using a design that reduces deflection to certain directions. For example, an elastomeric bearing is comprised of layers of a deformable elastomer material and layers of a rigid material. As used herein, "rigid" material is material that does not have deflection. The rigid layers may be placed between elastomeric layers such that the rigid layers slide with resistance relative to each other but the separation or compression of the rigid layers is prevented by the stacking of the elastomeric material in thin layers between the rigid layers.

Different types of dampers are used in different situations, depending on the desired degrees of freedom of the objects and the types of loads to be applied to the objects. For example, an elastomeric bearing may be used between two parts of a deck in a bridge such that these parts may expand or contract in response to changes in temperature. As another example, an elastomeric bearing may be used in a rotor assembly for a helicopter to absorb energy from dynamic loads and vibrations from rotor blades.

The elastomeric bearing used in one situation may not function as well as desired in another situation. For example, the loads and force directions that are encountered by an elastomeric bearing used in a bridge may be very different from the loads and force directions encountered by an elastomeric bearing used in a rotor assembly for a helicopter. As a result, the desired geometry, quantity, and thickness of

2

layers within an elastomeric bearing for one application may differ from the desired geometry, quantity, and thickness of layers for other applications.

Thus, as new applications using elastomeric bearings are implemented, new bearing designs are developed to provide a level of resistance that reduces the amount of deflection to a level desired for the new application. Therefore, it would be desirable to have a method and apparatus that takes into account at least some of the issues discussed above, as well as other possible issues.

SUMMARY

In one illustrative configuration, an apparatus comprises a multi-directional joint assembly and a damper. The multi-directional joint assembly has a first end and a second end. The first end and the second end move relative to each other. The damper is comprised of a number of elastomeric layers and a number of rigid layers interspersed with each other.

In another illustrative configuration, a multi-directional elastomeric dampened ball joint assembly comprises a ball, a socket, and a hemispherical elastomeric bearing. The ball is associated with a first end of the multi-directional elastomeric dampened ball joint assembly. The socket is associated with a second end of the multi-directional elastomeric dampened ball joint assembly. The ball is moveably held in a cavity in the socket. The hemispherical elastomeric bearing has alternating rigid layers and elastomeric layers. The outer surface of the hemispherical elastomeric bearing is associated with an inner surface of an enclosure. The inner surface of the hemispherical elastomeric bearing is associated with an outer surface of the socket. The hemispherical elastomeric bearing absorbs energy and reduces at least one of a force and a moment applied to at least one of the first end and the second end.

In yet another illustrative configuration, a method for reducing a force is provided. At least one of a number of forces and a number of moments is applied to at least one of a first end and a second end of a multi-directional joint assembly is received. The first end and the second end move relative to each other. A number of elastomeric layers in a damper associated with the multi-directional joint assembly are deformed. The damper comprises the number of elastomeric layers and a number of rigid layers interspersed with each other.

The features and functions can be achieved independently in various configurations of the present disclosure or may be combined in yet other configurations in which further details can be seen with reference to the following description and drawings.

BRIEF DESCRIPTION OF THE DRAWINGS

The novel features believed characteristic of the illustrative configurations are set forth in the appended claims. The illustrative configurations, however, as well as a preferred mode of use, further objectives and features thereof, will best be understood by reference to the following detailed description of an illustrative configuration of the present disclosure when read in conjunction with the accompanying drawings, wherein:

FIG. 1 is an illustration of a load environment in accordance with an illustrative configuration;

FIG. 2 is an illustration of a block diagram of a joint system in accordance with an illustrative configuration;

FIG. 3 is a detailed illustration of a joint system in accordance with an illustrative configuration;

3

FIG. 4 is an illustration of a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 5 is another illustration of a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 6 is an illustration of an exploded view of a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 7 is an illustration of a cross-sectional view of a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 8 is an exposed isometric view of a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 9 is an illustration of a torsional force applied to a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 10 is another illustration of a torsional force applied to a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 11 is an illustration of a cross-sectional view of a bending force applied to a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 12 is another illustration of a cross-sectional view of a bending force applied to a multi-directional joint assembly in accordance with an illustrative configuration;

FIG. 13 is a detailed illustration of layers in an elastomeric bearing in accordance with an illustrative configuration;

FIG. 14 is an illustration of layers in an elastomeric bearing in a loaded condition in accordance with an illustrative configuration;

FIG. 15 is an illustration of a flowchart of a process for absorbing a force in accordance with an illustrative configuration; and

FIG. 16 is another illustration of a flowchart of a process for absorbing a force in accordance with an illustrative configuration.

DETAILED DESCRIPTION

The illustrative configurations recognize and take into account one or more different considerations. For example, the illustrative configurations recognize and take into account that in some cases, it may be desirable to maintain a relative position between two objects within desired tolerances.

The illustrative configurations recognize and take into account that a spacing structure such as a beam may be used to maintain a desired distance between the two objects. The desired distance may be a required distance for the operation of the two objects or may be based on other considerations, depending on the particular implementation. The beam may be used to connect two objects to each other to ensure the required distance between the two objects is maintained while allowing relative movements within desired tolerances. For example, the beam may be connected to the objects such that relative movement up, down, left, and right occurs within desired tolerances. Similarly, the connection may also allow rotational movement within desired tolerances. Rotational movement is also known as torsional movement in these illustrative examples.

The illustrative configurations also recognize and take into account that a joint may be designed to limit degrees of freedom with respect to the movement of the objects relative to each other. When the type of movement that is provided, limited, or provided and limited includes angular and rotational movement, the joint may take the form of a multi-

4

directional joint assembly. When the type of movement that is provided, limited, or provided and limited includes angular movement only, the joint may take the form of a U-joint.

Additionally, the illustrative configurations recognize and take into account that movement of the two objects relative to each other may result in different types of forces being applied to the two objects connected to each other with a beam. For example, these forces may include one or more of a torsional force, a bending force, and a normal force. In these illustrative examples, a normal force may be a tension force or a compression force.

The illustrative configurations also recognize and take into account that deflection may be desired to reduce loads at the joint between the beam and the objects, where bending forces are highest. This type of movement may be facilitated using a multi-directional joint assembly with a damper. This damper deforms and reduces the load. In particular, the joints between objects may include a damper in the form of an elastomeric bearing.

Moreover, the illustrative configurations recognize and take into account that elastomeric bearings are well suited as dampers when loads occur simultaneously in different situations. In this case, joints may take the form of ball joints. A ball joint with an elastomeric bearing may be used to carry normal force through the ball joint to maintain a desired distance between objects while still allowing bending or torsional deflection within desired tolerances.

The illustrative configurations also recognize and take into account that an elastomeric bearing includes several layers of an elastomer that deform under a load. This deformation results in relative movement of the objects attached to opposite sides of the elastomeric bearing. The elastomer is a polymeric material. When a load is applied to the polymeric material, the polymeric material deforms in shear. When the load is removed, the polymeric material returns to substantially its original shape. In other words, the polymeric material returns to its original shape within selected tolerances. As used herein, "shear" stress is stress which is applied parallel or tangential to a face of a material.

With reference now to the figures and, in particular, with reference to FIG. 1, an illustration of a load environment is depicted in accordance with an illustrative configuration. As depicted, load environment 100 includes helicopter 102, helicopter 104, and helicopter 106. Helicopter 102, helicopter 104, and helicopter 106 move object 108. Object 108 may take various forms. For example, object 108 may be a container, a vehicle, a payload, or some other suitable type of object.

As depicted, object 108 is connected to helicopter 102, helicopter 104, and helicopter 106 by the line 110, line 112, and line 114, respectively. In this example, the weight of object 108 may pull helicopter 102, helicopter 104, and helicopter 106 toward each other during flight. As a result, spacing is maintained between helicopter 102, helicopter 104, and helicopter 106 using beam 116, beam 118, and beam 120. In these illustrative examples, beam 116 is connected to helicopter 102 and helicopter 106, beam 118 is connected to helicopter 102 and helicopter 104, and beam 120 is connected to helicopter 104 and helicopter 106.

The connections of beam 116, beam 118, and beam 120 to helicopter 102, helicopter 104, and helicopter 106 may be made using joint system 122, joint system 124, and joint system 126. Each joint system comprises a number of joint assemblies. In these illustrative examples, a joint system may comprise two joint assemblies with each joint assembly connecting a helicopter to a beam. Within each joint assembly, a multidirectional joint and a damper may be present.

5

As depicted, joint system 122 is associated with helicopter 102, beam 116, and beam 118. In other words, a first joint in joint system 122 connects helicopter 102 with beam 116 and a second joint connects helicopter 102 with beam 118. Similarly, joint system 124 is associated with helicopter 104, beam 118, and beam 120. Joint system 126 is associated with helicopter 106, beam 120, and beam 116.

When one component is “associated” with another component, the association is a physical connection in these depicted examples. For example, a first component, a joint in joint system 122, may be considered to be associated with a second component, helicopter 102, by being secured to the second component, bonded to the second component, mounted to the second component, welded to the second component, fastened to the second component, and/or connected to the second component in some other suitable manner. The first component also may be connected to the second component using a third component. The first component may also be considered to be associated with the second component by being formed as part of and/or as an extension of the second component.

With this configuration of helicopter 102, helicopter 104, and helicopter 106, many different forces may occur while carrying object 108. In this depicted example, the forces include horizontal forces that pull helicopter 102, helicopter 104, and helicopter 106 toward each other. These forces may be reacted by compressive loads carried through beam 116, beam 118, and beam 120. For example, a force pulling helicopter 102 toward helicopter 104 results in a compressive load being reacted through beam 118 in these illustrative examples.

The compressive forces within one or more of beam 116, beam 118, and beam 120 also may be introduced into the airframe of one or more of helicopter 102, helicopter 104, and helicopter 106 using various mechanisms. For example, a fixed joint, a flexible beam, a hydraulic actuator, a multi-directional joint, or other suitable types of mechanisms may be used.

In one example, joint system 122, joint system 124, and joint system 126 may be fixed joint systems. This type of joint system, however, may not provide a desired amount of movement between helicopter 102, helicopter 104, and helicopter 106 relative to each other. Without relative movement between helicopter 102, helicopter 104, and helicopter 106, the fixed joint system will induce bending loads, torsional loads, or both to be reacted at joint system 122, joint system 124, and joint system 126. These loads may be undesirable in these illustrative examples.

In another example, beam 116, beam 118, and beam 120 may be designed to allow for deflection. This type of beam design, however, limits the deflection properties of the system to the material and geometry selected for beam 116, beam 118, and beam 120. In other words, the material and geometry selected for beam 116, beam 118, and beam 120 determines the maximum amount of deflection possible for the system. Further, designing beam 116, beam 118, and beam 120 to allow deflection may compromise the compressive load capability of the beams, increase beam weight, or both. Additionally, the selection of a flexible material for beam 116, beam 118, and beam 120 does not directly address bending loads at the joints where the bending force is highest. Thus, designing beam 116, beam 118, and beam 120 to allow for deflection may be undesired in these illustrative examples.

In yet another example, hydraulic actuators may be used in joint system 122, joint system 124, and joint system 126. Hydraulic actuators, however, may not provide movement in

6

as many directions as desired. For example, because hydraulic actuators are linear acting, joint system 122, joint system 124, and joint system 126 would require additional support structures with multiple hydraulic actuators to accommodate various degrees of freedom. As a result, the use of multiple hydraulic actuators to provide movement in a desired number of directions may increase system complexity and cost.

In this illustrative example, joint system 122, joint system 124, and joint system 126 each have joints that allow for movement in a desired number of directions. An illustrative configuration may be implemented in joint system 122, joint system 124, and joint system 126. In particular, joint system 122, joint system 124, and joint system 126 may employ multi-directional joints such as ball joints. A more detailed illustration of joint system 122 in section 128 is shown and described with respect to FIG. 3, below.

In these illustrative examples, an illustrative configuration may be implemented in one or more of joint system 122, joint system 124, and joint system 126 to maintain the movement of a beam and a helicopter relative to each other within a desired tolerance. For example, an illustrative configuration may be implemented in joint system 122 to maintain movement of beam 116 relative to helicopter 102 within a desired tolerance of five feet. Of course, the desired tolerance may be any distance, depending on the particular implementation.

Further, an illustrative configuration may be implemented in joint system 122, joint system 124, and joint system 126 to reduce a force, absorb the force, dampen the force, or some combination thereof with respect to forces that may be applied to joint system 122, joint system 124, and joint system 126 during operation of helicopter 102, helicopter 104, and helicopter 106. Moreover, an illustrative configuration may be implemented in joint system 122, joint system 124, and joint system 126 to reduce a moment, absorb the moment, dampen the moment, or some combination thereof with respect to moments that may be applied to joint system 122, joint system 124, and joint system 126. As used herein a “moment” is a force acting over a distance.

For example, an illustrative configuration may include an apparatus that may be implemented in at least one of joint system 122, joint system 124, and joint system 126. In one or more illustrative configurations, an apparatus comprises a multi-directional joint assembly and a damper. The multi-directional joint assembly has a first end and a second end. The first end and the second end move relative to each other. The damper is associated with the multi-directional joint assembly. The damper is comprised of a number of rigid layers and a number of elastomeric layers interspersed with each other. As used herein, a “number of,” when used with reference to items, means one or more items. For example, a number of rigid layers is one or more rigid layers.

Turning next to FIG. 2, an illustration of a block diagram of a joint system is depicted in accordance with an illustrative configuration. Joint system 200 is an example of a joint system that may be used to implement at least one of joint system 122, joint system 124, and joint system 126 in load environment 100 in FIG. 1.

As used herein, the phrase “at least one of,” when used with a list of items, means different combinations of one or more of the listed items may be used and only one of each item in the list may be needed. For example, “at least one of item A, item B, and item C” may include, without limitation, item A or item A and item B. This example also may include item A, item B, and item C or item B and item C. In other examples, “at least one of” may be, for example, without

limitation, two of item A, one of item B, and ten of item C; four of item B and seven of item C; and other suitable combinations.

As depicted, joint system **200** includes number of joint assemblies **201**. Multi-directional joint assembly **202** is a joint assembly in number of joint assemblies **201** in which an illustrative configuration may be implemented. In particular, multi-directional joint assembly **202** may include multi-directional joint **204** and damper **215**. In these illustrative examples, multi-directional joint **204** may be a ball joint. Of course, multi-directional joint assembly **202** may comprise other types of multi-directional joints other than a ball joint, depending on the particular implementation.

In this illustrative example, multi-directional joint assembly **202** has first end **206** and second end **208**. First end **206** is connected to first object **210**, while second end **208** is connected to second object **212**. For example, first end **206** may be connected to beam **116** and second end **208** may be connected to a rotorcraft such as helicopter **102** in FIG. 1.

As depicted, first object **210** and second object **212** may take different forms depending on the particular implementation. In one illustrative example, first object **210** may be beam **116**, while second object **212** may be helicopter **102**.

As used herein, a first component that is "connected to" a second component means that the first component can be connected directly or indirectly to the second component. In other words, additional components may be present between the first component and the second component. The first component is considered to be indirectly connected to the second component when one or more additional components are present between the two components. When the first component is directly connected to the second component, no additional components are present between the two components.

As depicted, multi-directional joint **204** has ball **213** and socket **214**. First end **206** of multi-directional joint assembly **202** is associated with ball **213** of multi-directional joint **204** and second end **208** of multi-directional joint assembly **202** is associated with socket **214** of multi-directional joint **204**. As depicted, ball **213** and socket **214** are physical structures. Socket **214** holds ball **213**.

Further, multi-directional joint assembly **202** also includes damper **215** within interior **216** of multi-directional joint assembly **202**. In this illustrative example, damper **215** is elastomeric structure **218**. In particular, damper **215** may be elastomeric bearing **220**.

Still more particularly, multi-directional joint assembly **202** may take the form of multi-directional elastomeric dampened ball joint assembly **222**. In this form, multi-directional elastomeric dampened ball joint assembly **222** may aid in the absorption of number of forces **223**. Number of forces **223** may include, for example, at least one of a torsional force, a compressive force, a bending force, a tension force, and other suitable types of forces. In this example, multi-directional elastomeric dampened ball joint assembly **222** may dampen number of forces **223**. This dampening may include reducing vibrations in some instances.

In this illustrative example, damper **215** is comprised of layers **224**. In particular, layers **224** may include number of elastomeric layers **226** and number of rigid layers **228**.

In the illustrative example, number of elastomeric layers **226** and number of rigid layers **228** are interspersed with each other. In other words, layers **224** may alternate between an elastomeric layer and a rigid layer. In yet another illustrative example, layers **224** may have two elastomeric layers and three rigid layers. The manner in which layers **224**

alternate between different types of layers may vary depending on the particular implementation.

An elastomeric layer in number of elastomeric layers **226** is a layer that deforms in response to number of loads **230**. Number of loads **230** may be input loads **231**. As depicted, number of loads **230** may be a force applied to damper **215** from other components in multi-directional joint assembly **202**.

When number of loads **230** is reduced or removed to a sufficient level, the elastomeric layer in number of elastomeric layers **226** may substantially return to its original shape. In other words, the elastomeric layer in number of elastomeric layers **226** may return to its original shape within selected tolerances.

In these depicted examples, an elastomeric layer may be, for example, a polymer. The polymer may have a viscoelasticity that has a desired Young's modulus and a desired yield strain. The desired Young's modulus may be low and the desired yield strain may be high compared to other materials in damper **215** such as a rigid layer in number of rigid layers **228**.

In these illustrative examples, number of elastomeric layers **226** may be comprised of a number of materials with a desired viscoelasticity. The number of materials may be selected from at least one of neoprene, rubber, an elastic polymer, a thermoplastic elastomer, synthetic polyisoprene, polybutadiene, ethylene-vinyl acetate, chlorosulfonated polyethylene, and other suitable materials.

A rigid layer may not have the same properties found in an elastomeric layer. A rigid layer is configured with a low Young's modulus to force the deflection to take place in elastomeric layers only. By stacking alternating rigid layers and elastomeric layers, material deformation of elastomeric layers in response to normal forces is arrested as a result of the neighboring rigid layers which limit flow of deformed material. As a result, deformation occurs in response to shear loads only since deflection in response to normal forces is arrested by rigid layers.

In these illustrative examples, number of rigid layers **228** also may be comprised of a number of materials. The number of materials selected for number of rigid layers **228** may be selected from a metal such as, for example, without limitation, aluminum, steel, titanium, or other suitable materials.

The thicknesses used for number of elastomeric layers **226** and number of rigid layers **228** in layers **224** may vary depending on the amount of elastomeric bearing movement that may be desired for a given input load. In other words, if a larger amount of movement for elastomeric bearing **220** is desired, an increased quantity, thickness, or both for number of elastomeric layers **226** may be used. Conversely, if little movement of elastomeric bearing **220** is desired, a decreased quantity, thickness, or both for number of elastomeric layers **226** may be used. Increasing or decreasing the Young's modulus of the elastomeric material will also increase or decrease the amount of deflection for a given load.

Further, different layers may have different thicknesses within number of elastomeric layers **226**, depending on the desired movement of elastomeric bearing **220**. In a similar fashion, the number of rigid layers **228** also may have different thicknesses. These thicknesses may be selected such that number of elastomeric layers **226** and number of rigid layers **228** perform as desired.

In these illustrative examples, number of loads **230** may occur in response to at least one of number of forces **223** and number of moments **225** being applied to at least one of first

end **206** and second end **208** of multi-directional joint assembly **202**. Number of forces **223** may be a single force or may be a combination of forces that may be applied to one or both of first end **206** and second end **208**. In these illustrative examples, number of forces **223** may include at least one of a normal force, a reaction force, a portion force, a bending force, and other types of forces. Number of moments **225** may include at least one of torsion, a bending moment, and other types of moments.

In this example, damper **215** carries bending and torsional loads and deflects in these directions. Normal loads from structures connected to multi-directional joint assembly **202** are reacted through multi-directional joint **204**.

As depicted in these illustrative examples, damper **215** may absorb energy from number of forces **223** and number of moments **225** applied to multi-directional joint assembly **202**. For example, damper **215** absorbs energy from bending and torsional complements comprising number of loads **230**. The absorption of initial energy **234** in the deformation of number of elastomeric layers **226** results in heat **236** being released. In other words, number of forces **223** causing number of loads **230** may be reduced by absorbing initial energy **234** in the form of deformation **237** of number of elastomeric layers **226** and releasing heat **236** in these illustrative examples.

Output loads **235** are then carried through first end **206** into first object **210** and through second end **208** into second object **212**. Because initial energy **234** is absorbed by number of elastomeric layers **226**, output loads **235** are less than input loads **231** in these illustrative examples. In other words, output loads **235** are reduced loads. In this manner, an illustrative configuration may provide a desired level of movement of first object **210** and second object **212** relative to each other while preventing undesired movement of first object **210**, second object **212**, or both.

The illustration of joint system **200** in FIG. 2 is not meant to imply physical or architectural limitations to the manner in which an illustrative configuration may be implemented. Other components in addition to or in place of the ones illustrated may be used. Some components may be unnecessary. Also, the blocks are presented to illustrate some functional components. One or more of these blocks may be combined, divided, or combined and divided into different blocks when implemented in an illustrative configuration.

For example, additional joint assemblies may be present in addition to multi-directional joint assembly **202**. In still other illustrative examples, an additional structure in addition to or in place of damper **215** also may be present within multi-directional joint assembly **202**. This additional structure also may absorb loads such as number of loads **230** and generate heat **236** from initial energy **234** in number of loads **230** such that multi-directional joint **204** performs as desired.

With reference now to FIG. 3, a detailed illustration of a joint system is depicted in accordance with an illustrative configuration. In this figure, a more detailed illustration of section **128** in FIG. 1 is shown.

As depicted, joint system **122** includes multi-directional joint assembly **300** and multi-directional joint assembly **302**. Multi-directional joint assembly **300** and multi-directional joint assembly **302** are examples of physical implementations for multi-directional joint assembly **202** with multi-directional joint **204** and damper **215** shown in block form in FIG. 2. A multi-directional joint and a damper (not shown) are located within each of multi-directional joint assembly **300** and multi-directional joint assembly **302** in these depicted examples.

In this illustrative example, multi-directional joint assembly **300** has first end **304** and second end **306**. First end **304** is associated with beam **116**, and second end **306** is associated with helicopter **102**. Multi-directional joint assembly **302** has first end **308** and second end **310**. First end **308** is associated with beam **118**, and second end **310** is associated with helicopter **102**.

As depicted, first end **304**, second end **306**, first end **308**, and second end **310** are physical structures. First end **304**, second end **306**, first end **308**, and second end **310** provide locations on multi-directional joint assembly **300** and multi-directional joint assembly **302** that may be associated with other structures.

In this illustration, beam **116** and beam **118** are shown in phantom. This view of beam **116** and beam **118** is provided to illustrate the connection of first end **304** with beam **116** and first end **308** with beam **118**.

In these illustrative examples, different forces may occur that apply loads to multi-directional joint assembly **300** or multi-directional joint assembly **302** during the operation of the helicopters carrying object **108** in FIG. 1. For example, a force may be applied in the direction of arrow **314**, arrow **316**, and arrow **320**. Arrow **314** represents a bending force. As another example, arrow **316** represents a torsional force. The torsional force represented by arrow **316** is applied rotationally about axis **318** in this illustrative example. As yet another example, arrow **320** represents an example of a compressive force. This compression force may be applied along axis **318**.

This illustration of the different types of forces is depicted to provide an example of some of the types of forces that may be applied to a multi-directional joint assembly in joint system **122**. Of course, other types of forces may be applied in addition to or in combination with the forces illustrated in this example.

Turning now to FIG. 4, an illustration of a multi-directional joint assembly is depicted in accordance with an illustrative configuration. In this example, a more detailed illustration of multi-directional joint assembly **300** in FIG. 3 is shown in a perspective view.

In this illustration, multi-directional joint assembly **300** is shown without the components that may be associated with or connected to first end **304** and second end **306** of multi-directional joint assembly **300**. First end **304** and second end **306** move relative to each other in bending. This movement may also include torsional movement.

In FIG. 5, another illustration of a multi-directional joint assembly is depicted in accordance with an illustrative configuration. In this figure, another perspective view of multi-directional joint assembly **300** is shown from second end **306**.

With reference now to FIG. 6, an illustration of an exploded view of a multi-directional joint assembly is depicted in accordance with an illustrative configuration. As can be seen in this exploded view, multi-directional joint assembly **300** includes a number of different components. As depicted, multi-directional joint assembly **300** includes enclosure **600**. In this particular example, enclosure **600** is comprised of first portion **603** and second portion **605**. Multi-directional joint assembly **300** also includes ring **601**, ball **602**, socket **604**, and elastomeric bearing **606**. Ring **601**, ball **602**, and socket **604** comprise multi-directional joint **607**. Multi-directional joint **607** may be one example of an implementation for multi-directional joint **204** shown in block form in FIG. 2.

First portion **603** and second portion **605** of enclosure **600** are physical structures that hold ball **602**, socket **604**, and

11

elastomeric bearing 606 within interior 610 of enclosure 600. Second portion 605 may be connected to first portion 603 of enclosure 600 of multi-directional joint assembly 300.

As depicted, ball 602 is a physical structure that is associated with first portion 603 of enclosure 600. In these illustrative examples, ball 602 may be formed as part of first portion 603 of enclosure 600 or may be connected to first portion 603 of enclosure 600 within interior 610 of first portion 603 of enclosure 600. Ball 602 has a shape of a sphere in this illustrative example.

In this example, socket 604 receives and hold ball 602. Ring 601 may be connected to socket 604 to retain ball 602 within socket 604. Ring 601 may be connected to socket 604 by being bonded, welded, or otherwise connected to socket 604.

Elastomeric bearing 606 takes a hemispherical form in this illustrative example. In these examples, a hemispherical elastomeric bearing is an elastomeric bearing that allows movement in multiple degrees of freedom. In other words, elastomeric bearing 606 allows movement in more than one direction.

As illustrated, multi-directional joint assembly 300 is rigid with respect to normal forces, such as compression and tension loads, reacted along axis 318. However, elastomeric bearing 606 reacts bending and torsional forces and enables load reduction in these directions through deflection in bending and torsion. In other words, the multi-directional joint assembly is rigid when reacting compression and tension loads introduced by a beam, but allows the beam to bend up, down, left, right, rotate, or some combination thereof relative to an airframe. This relative motion will be reduced to some amount of movement by the configuration of layers within elastomeric bearing 606. This reduction in the movement may be referred to as a limit to the movement of the beam.

As illustrated, elastomeric bearing 606 has opening 616 and second portion 605 of enclosure 600 has opening 618. Opening 616 and opening 618 allows second end 306 to extend through opening 616 and opening 618. As depicted, elongate member 620 associates second end 306 with second portion 605 of enclosure 600. Opening 616 and opening 618 also allows second end 306 to move in a number of different directions.

In this illustrative example, first portion 603, ball 602, socket 604, second portion 605, and ring 601 may be comprised of a material selected from at least one of a metal, a plastic, a polycarbonate, aluminum, copper, titanium, steel, and other suitable materials. The material selected for first portion 603, ball 602, socket 604, second portion 605, and ring 601 may be one that may withstand the forces, environment, and other conditions that multi-directional joint assembly 300 may be exposed to during use of multi-directional joint assembly 300. Different components may be comprised of different materials.

In this particular example, the elastomeric layers in elastomeric bearing 606 are formed using neoprene. Of course, the material selected for the elastomeric layers may be any material that provides a desired level of viscoelasticity.

Turning now to FIG. 7, an illustration of a cross-sectional view of a multi-directional joint assembly is depicted in accordance with an illustrative configuration. In this figure, a cross-sectional view of multi-directional joint assembly 300 is shown taken along lines 7-7 in FIG. 4.

12

In this cross-sectional view, elongate member 700 extends from ball 602 to first end 304. Additionally, ball 602 can be seen as being retained within cavity 702 of socket 604 by ring 601.

As depicted, elastomeric bearing 606 is comprised of layers 704. Layers 704 are an example of number of elastomeric layers 226 shown in block form in FIG. 2.

As can be seen in section 705, layers 704 alternate between elastomeric layers and rigid layers. In this example, elastomeric layer 706 is located between rigid layer 708 and second portion 605 of enclosure 600. In particular, elastomeric layer 706 may be associated with inner surface 707 of second portion 605. Second portion 605 may function as a rigid layer and may be considered a rigid layer in this particular example. As another example, elastomeric layer 712 is located between rigid layer 714 and rigid layer 716 in layers 704. Rigid layer 714 is associated with outer surface 717 of socket 604. In other illustrative examples, some portions of layers 704 may not be associated with each other or may not be associated with second portion 605 of enclosure 600, socket 604, or both, depending on the particular implementation.

In this illustrative example, the different layers in layers 704 are associated with each other such that layers 704 do not slide relative to each other. In other words, a layer in layers 704 will not slide across the surface of another layer in layers 704 or separate from other layers in layers 704 in some other manner. Layers within layers 704 may be bonded to each other or secured to one another in some other suitable manner.

Turning now to FIG. 8, an exposed isometric view of a multi-directional joint assembly is depicted in accordance with an illustrative configuration. An exposed isometric view of multi-directional joint assembly 300 is shown in a static state. In this state, no bending or torsional forces are applied to multi-directional joint assembly 300.

In FIG. 9, an illustration of a torsional force applied to a multi-directional joint assembly is depicted in accordance with an illustrative configuration. As depicted, torsional force 900 is applied to multi-directional joint assembly 300. In this example, torsional force 900 is a force in a direction about axis 318 that extends centrally through multi-directional joint assembly 300. Torsional force 900 is applied in a clockwise direction at first end 304 of multi-directional joint assembly 300 in this illustrative example. Torsional force 900 may cause ball 602 to rotate relative to socket 604 about axis 318.

Torsional force 900 is reacted by elastomeric bearing 606. In particular, elastomeric bearing 606 incurs a deflection in rotation that absorbs energy and reduces the torsional load carried between first end 304 and second end 306 of multi-directional joint assembly 300. This load will occur when the first end 304 and second end 306 rotate relative to each other along axis 318. At least a portion of this energy may be converted into heat in this illustrative example.

When torsional force 900 is no longer applied at first end 304, elastomeric bearing 606 may substantially return to the original state as illustrated in FIG. 8. In this manner, elastomeric bearing 606 absorbs energy from torsional force 900 while multi-directional joint assembly 300 remains rigid along axis 318 to maintain a desired relative distance between a first object associated with first end 304 and a second object associated with second end 306 of multi-directional joint assembly 300. In this particular example, energy is not absorbed in other directions such as bending.

With reference next to FIG. 10, another illustration of a torsional force applied to a multi-directional joint assembly

13

is depicted in accordance with an illustrative configuration. In this example, torsional force **1000** is applied at first end **304** of multi-directional joint assembly **300**. Torsional force **1000** is applied in an opposite direction to torsional force **900** in FIG. 9. In this depicted example, torsional force **1000** is applied in a counterclockwise direction about axis **318**.

The application of torsional force **1000** also may cause a load to be applied on elastomeric bearing **606** that causes elastomeric bearing **606** to deform. This deformation also absorbs energy from the load placed on elastomeric bearing **606** through deformation that results from reacting torsional force **1000**. When torsional force **1000** is no longer applied at first end **304**, elastomeric bearing **606** may substantially return to its original state as illustrated in FIG. 8.

With reference now to FIG. 11, an illustration of a cross-sectional view of a bending force applied to a multi-directional joint assembly is depicted in accordance with an illustrative configuration. In this cross-sectional view taken along lines 7-7 in FIG. 4, bending force **1100** is applied at first end **304** of multi-directional joint assembly **300**. In this illustrative example, bending force **1100** is applied relative to axis **318**. In particular, bending force **1100** may be perpendicular to or at some other angle relative to axis **318**.

Bending force **1100** results in a load being reacted by elastomeric bearing **606**. With a beam type configuration as used in this illustrative example, the bending load component is greater than the normal loads or torsional loads. Reaction of this load causes a deformation of elastomeric bearing **606**. This load occurs where first end **304** rotates relative to second end **306** at any axis perpendicular to axis **318**. Since the outer surface of elastomeric bearing **606** is attached to second portion **605** of enclosure **600** and the inner surface of elastomeric bearing **606** is attached to socket **604**, any bending loads applied to the joint system are reacted by elastomeric bearing **606**. Energy from the load causing deformation by means of bending force **1100** may be converted into heat in elastomeric bearing **606**.

When bending force **1100** is no longer applied at first end **304**, a load is no longer applied to elastomeric bearing **606**. As a result, elastomeric bearing **606** may return to substantially its original state as shown in FIG. 8.

Next, in FIG. 12, another illustration of a cross-sectional view of a bending force applied to a multi-directional joint assembly is depicted in accordance with an illustrative configuration. In this cross-sectional view taken along lines 7-7 in FIG. 4, bending force **1200** is applied at first end **304**. Bending force **1200** is opposite to bending force **1100** in FIG. 11 relative to axis **318**.

In these illustrative examples, the application of bending force **1200** applies a load to elastomeric bearing **606** that causes the deformation of elastomeric bearing **606**. Energy from bending force **1200** is absorbed by deforming elastomeric bearing **606**. Some of this energy may also be converted to heat as a result of deforming elastomeric bearing **606**. When bending force **1200** is removed, elastomeric bearing **606** may substantially return to its original state as illustrated in FIG. 8.

In FIG. 13, a detailed illustration of layers in an elastomeric bearing is depicted in accordance with an illustrative configuration. A more detailed illustration of layers **704** in section **705** from FIG. 7 is shown. In particular, elastomeric layer **712** is depicted between rigid layer **714** and rigid layer **716**. Layers **704** are depicted in an unloaded state.

With reference next to FIG. 14, an illustration of layers in an elastomeric bearing in a loaded condition is depicted in accordance with an illustrative configuration. As seen in this figure, layers **704** are shown as deformed in response to

14

force **1400** being applied to one end of multi-directional joint assembly **300**. Force **1400** causes the load to deform elastomeric layers in layers **704** in elastomeric bearing **606**.

As can be seen, the rigid layers in layers **704** within elastomeric bearing **606** have moved relative to each other. This movement is facilitated by deformation of the elastomeric layers in shear reacting to force **1400**.

In particular, rigid layer **714** and rigid layer **716** have moved relative to each other because elastomeric layer **712** has deformed in shear. Similarly, the other rigid layers move relative to each other due to deformation in the other elastomeric layers in layers **704**. When force **1400** is removed, layers **704** may return to the state as shown in FIG. 13.

In this manner, a first object associated with first end **304** of multi-directional joint assembly **300** and a second object associated with second end **306** of multi-directional joint assembly **300** may move relative to each other. However, this movement is limited by the configuration of layers **704** in elastomeric bearing **606**.

The illustration of multi-directional joint assembly **300** in FIGS. 3-14 is provided only for purposes of illustrating one manner in which multi-directional joint **204** shown in block form in FIG. 2 may be implemented. These illustrations of multi-directional joint assembly **300** are not meant to imply limitations to the manner in which different illustrative configurations may be implemented.

For example, although the different elastomeric layers in layers **704** in elastomeric bearing **606** are shown as having the same thickness, other thicknesses may be present such that different layers within the elastomeric layers may have different thicknesses. In a similar fashion, different rigid layers in layers **704** of elastomeric bearing **606** also may have different thicknesses. Further, although 18 layers are shown in layers **704**, other numbers of elastomeric layers and rigid layers may be present in elastomeric bearing **606**, depending on the desired functionality for elastomeric bearing **606**.

The different components shown in FIG. 1 and FIGS. 3-14 may be combined with components in FIG. 2, used with components in FIG. 2, or a combination of the two. Additionally, some of the components in FIG. 1 and FIGS. 3-14 may be illustrative examples of how components shown in block form in FIG. 2 can be implemented as physical structures.

With reference now to FIG. 15, an illustration of flowchart of a process for absorbing a force is depicted in accordance with an illustrative configuration. The process illustrated in FIG. 15 may be implemented in load environment **100** in FIG. 1. In particular, the processes may be implemented using joint system **200** in FIG. 2.

At least one of a number of forces and a number of moments is received in which the number of forces and the number of moments are applied to at least one of a first end and a second end of a multi-directional joint assembly (operation **1500**). The first end and the second end move relative to each other in the multi-directional joint assemblies. This movement may occur as a result of forces and/or moments applied to at least one of the first end and the second end. A number of elastomeric layers and a structure in the joint are deformed (operation **1502**). The number of elastomeric layers is located in a structure in the multi-directional joint assembly. The number of elastomeric layers is interspersed with a number of rigid layers within the structure.

The process absorbs energy from the at least one of the number of forces and the number of moments through the

15

deformation of the number of elastomeric layers (operation **1504**) with the process terminating thereafter. This absorption of energy may be released as heat in these illustrative examples.

With reference now to FIG. **16**, another illustration of a flowchart of a process for absorbing a force is depicted in accordance with an illustrative configuration. The process illustrated in FIG. **16** may be implemented in load environment **100** in FIG. **1**. In particular, the processes may be implemented using joint system **200** in FIG. **2**.

In this example, joint system **200** is used to maintain a fixed distance between a first object and a second object. Further, joint system **200** allows some amount of relative movement between the first object and the second object. The process begins by imposing at least one of forces and moments on the first object that are different than the forces and the moments imposed on the second object (operation **1600**). This first object may be first object **210** in FIG. **2** and may be an example of an object such as helicopter **102** in FIG. **1**. This second object may be second object **212** in FIG. **2** and may be a beam such as beam **116** in FIG. **1**.

A combination of the forces and the moments is applied to the joint system connecting the first object and the second object (operation **1602**). In these depicted examples, the difference in forces imposed on the first object and the second object causes a combination of normal, bending, and torsional forces to be applied to the joint system. Further, torsion, a bending moment, or other types of moments may be applied to the joint system. These forces and moments result in a number of loads being applied to the joint system.

As illustrated, the joint system is comprised of a third object that connects the first and second objects. For example, beam **116** may connect helicopter **102** to helicopter **106**. In this example, each end of the third object features a multi-directional joint assembly with an elastomeric bearing. In other words, one multi-directional joint assembly connects the first object to the third object and a second multi-directional joint assembly connects the second object to the third object. For example, a first multi-directional joint assembly connects helicopter **102** with beam **116** and a second multi-directional joint assembly connects beam **116** with helicopter **106** in these illustrative examples.

Next, a combination of normal, bending, and torsional loads are induced at the multi-directional joint assemblies between objects (operation **1604**). The normal load is reacted rigidly by the multi-directional joint assembly while the bending and torsional loads are reacted by the elastomeric bearing in the joint system such that the elastomeric bearing may deform. In this illustrative example, the combination of normal, bending, and torsional loads may be a result of the displacement of the first object, second object, third object, or some combination thereof. As a result, the normal loads are carried directly into helicopter **102** and helicopter **106** via multi-directional joint assemblies at the ends of beam **116**, while the bending and torsional loads are passed through the elastomeric bearings surrounding the multi-directional joint assemblies between these objects.

Next, elastomeric layers in the elastomeric bearing are deformed (operation **1606**). In this illustrative example, the bending and torsional loads reacted by the elastomeric bearing cause the deformation in the elastomeric layers. These elastomeric layers may be elastomeric layers within layers **704** of elastomeric bearing **606** in FIG. **7**. These elastomeric layers deform in shear and cause the rigid layers within layers **704** to move relative to each other. The elastomeric layers may deform a limited amount in response to the loads applied. For example, the elastomeric layers

16

may be configured such that the first object and the second object may move within five feet of each other.

Energy is then absorbed by the elastomeric layers in the elastomeric bearing (operation **1608**). This absorption of energy is caused by the deformation of the elastomeric layers and results in a reduction of the bending and torsional loads carried to the first and second objects. Heat is then released by the elastomeric layers (operation **1610**) with the process terminating thereafter. In this example, heat may be released as a result of the deformation of the elastomeric layers. The quantity of heat may vary depending on the material properties and the level of deformation imposed on the elastomeric layers.

The flowcharts and block diagrams in the different depicted configurations illustrate the architecture, functionality, and operation of some possible implementations of apparatuses and methods in an illustrative configuration. In this regard, each block in the flowcharts or block diagrams may represent a module, a segment, a function, and/or a portion of an operation or step.

In some alternative implementations of an illustrative configuration, the function or functions noted in the blocks may occur out of the order noted in the figures. For example, in some cases, two blocks shown in succession may be executed substantially concurrently, or the blocks may sometimes be performed in the reverse order, depending upon the functionality involved. Also, other blocks may be added in addition to the illustrated blocks in a flowchart or block diagram.

Thus, the illustrative configurations provide a method and apparatus for reducing a force in exchange for a deflection. With the use of an illustrative configuration, two objects connected by a multi-directional joint assembly may move relative to each other. However, this movement is limited by the type of multi-directional joint selected and the layer configuration of the elastomeric bearing. As a result, the illustrative configurations provide a stable joint that is rigid to normal forces but still allows movement in bending and torsion of two objects relative to each other within desired tolerances.

Moreover, because bending loads are typically the highest loads reacted by joints that separate objects, the load reduction afforded by the deformation of the elastomeric bearing allows the structural elements at the joint ends to be significantly reduced as compared to other currently used designs. In other words, because the deformation of elastomeric layers within the elastomeric bearing absorb energy from bending and torsional forces, the total force reacted by the first object, second object, and third object becomes much less. As a result, fewer structural elements to carry the same initial load are required. Consequently, the structures required on either side of a joint system connecting two objects may be lighter and smaller.

Thus, with the use of an illustrative configuration, the load within a system is reduced by allowing objects to move relative to each other in certain degrees of freedom as determined by the configuration of the multi-directional joint and damper.

The description of the different illustrative configurations has been presented for purposes of illustration and description, and is not intended to be exhaustive or limited to the configurations in the form disclosed. Many modifications and variations will be apparent to those of ordinary skill in the art.

For example, the illustrative configurations may be implemented for other purposes other than maintaining distance between multiple helicopters in load environment **100**. For

17

example, the different illustrative configurations may be applied for use in an automobile, joints for robots, mechanical linkages, or any application in which a controlled amount of relative movement between objects is desired.

Further, different illustrative configurations may provide different features as compared to other illustrative configurations. The configuration or configurations selected are chosen and described in order to best explain the principles of the configurations, the practical application, and to enable others of ordinary skill in the art to understand the disclosure for various configurations with various modifications as are suited to the particular use contemplated.

What is claimed is:

1. An apparatus comprising:

- a beam having a first end of a multi-directional joint assembly connected thereto, wherein the first end comprises a ball distally connected to the beam by a first elongate member and a first portion of an enclosure of the multi-directional joint assembly, the enclosure comprised of the first portion and a second portion, wherein the ball is held within an interior of the enclosure;
- a rotorcraft having a second end of the multi-directional joint assembly connected thereto, wherein the second end comprises a hemispherical socket distally connected to the rotorcraft by a second elongate member and extending through a hole in the second portion, wherein the ball is pivotally held within the hemispherical socket by a frusto-spherical ring directly connected to the hemispherical socket; and
- a damper disposed between the hemispherical socket and the second portion, wherein the damper is comprised of a number of elastomeric layers and a number of rigid layers interspersed with each other.

2. The apparatus of claim 1, wherein the damper is an elastomeric bearing.

3. The apparatus of claim 1, wherein the number of rigid layers and the number of elastomeric layers are associated with each other and the multi-directional joint assembly.

4. The apparatus of claim 1, wherein the number of elastomeric layers is comprised of a number of materials selected from the group of neoprene, a thermoplastic elastomer, synthetic polyisoprene, polybutadiene, ethylene-vinyl acetate, and chlorosulfonated polyethylene.

5. The apparatus of claim 1, wherein the number of rigid layers is selected from the group of a metal and a plastic.

6. The apparatus of claim 1, wherein the damper absorbs energy from a number of loads caused by at least one of a number of forces and a number of moments applied to at least one of the first portion and the second portion of the multi-directional joint assembly.

7. The apparatus of claim 6, wherein the number of forces is selected from at least one of a normal force, a torsional force, and a bending force, and wherein the number of moments is selected from one of torsion and a bending moment.

8. The apparatus of claim 1, wherein the damper is connected to the ball and the socket.

18

9. The apparatus of claim 8, wherein the multi-directional joint assembly further comprises:

- an elongate member extending from the ball, wherein the elongate member is associated with a cavity of the enclosure in which the ball and socket are located.

10. The apparatus of claim 9, wherein the damper is directly connected to the enclosure and the socket and is indirectly connected to the ball by the enclosure and the elongate member.

11. The apparatus of claim 1, wherein an outer surface of the socket contacts the damper.

12. The apparatus of claim 1, wherein the first portion and the second portion of the enclosure are connected at a second midpoint of the ball, and wherein the first midpoint and the second midpoint are the same when no bending force is applied to the multi-directional joint.

13. A multi-directional elastomeric dampened ball joint assembly comprising:

- a beam having a first end of a multi-directional joint assembly connected thereto;
- a rotorcraft having a second end of the multi-directional joint assembly connected thereto;
- an enclosure and a multi-directional joint, the enclosure comprised of a first portion and a second portion, wherein the multi-directional joint comprises a first end comprising a ball associated with the first portion and distally connected to the beam by a first elongate member;
- a second end comprising a hemispherical socket associated with the second portion and distally connected to the rotorcraft by a second elongate member and extending through a hole in the second portion, wherein the ball is moveably held in a cavity in the socket;
- a frusto-spherical ring directly connected to the hemispherical socket, wherein the ring pivotally holds the ball within the hemispherical socket; and
- a hemispherical elastomeric bearing disposed between the hemispherical socket and the second portion and having alternating rigid layers and elastomeric layers, wherein an outer surface of the hemispherical elastomeric bearing is associated with an inner surface of the enclosure, an inner surface of the hemispherical elastomeric bearing is associated with an outer surface of the socket, and wherein the hemispherical elastomeric bearing absorbs energy and reduces at least one of a force and a moment applied to at least one of the first portion and the second portion.

14. The multi-directional elastomeric dampened ball joint assembly of claim 13, wherein the ball, the socket, and the hemispherical elastomeric bearing are located within an interior of the enclosure.

* * * * *